

FIG.1

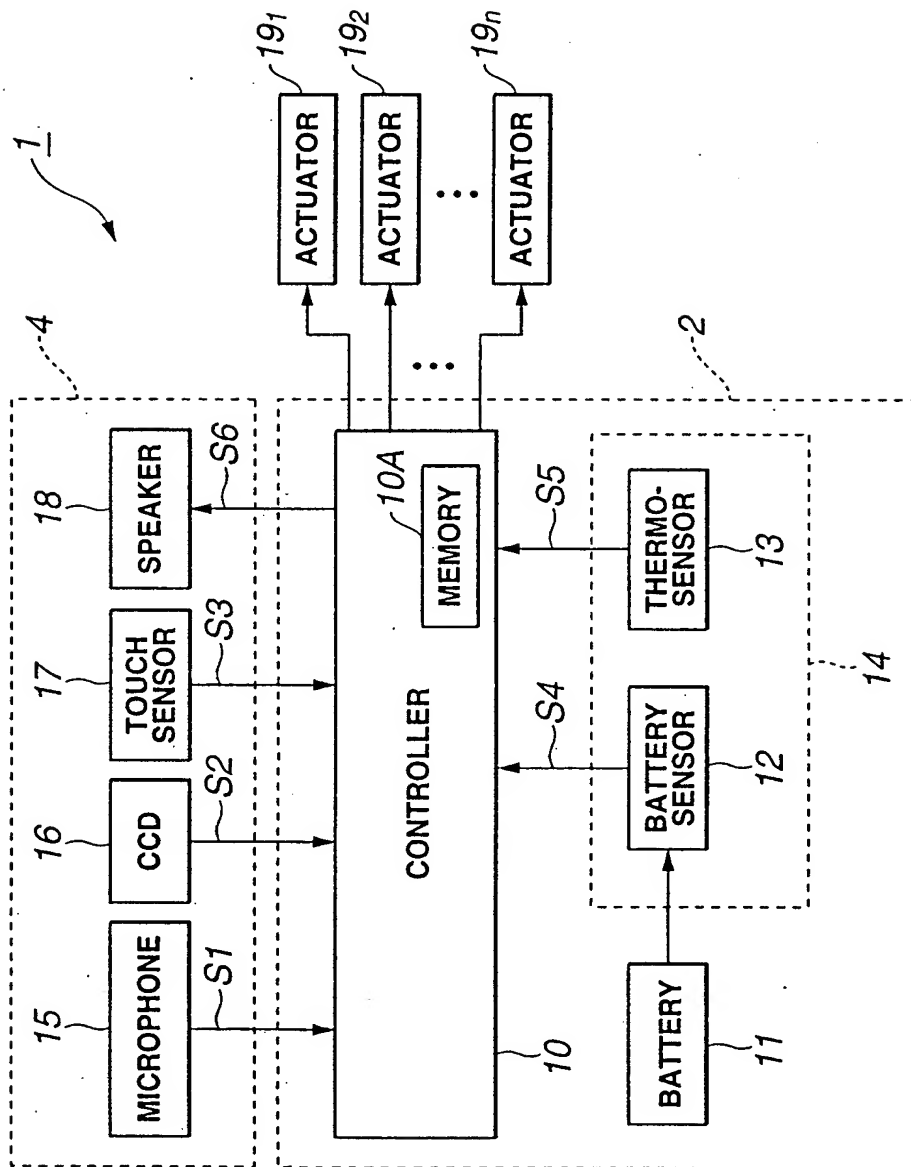


FIG.2

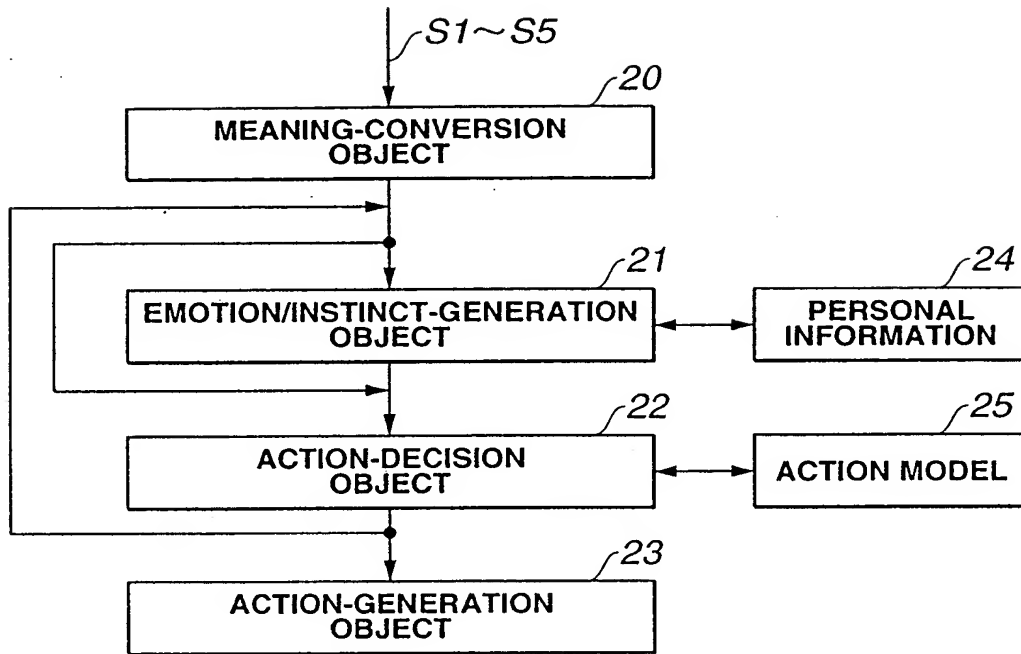


FIG.3

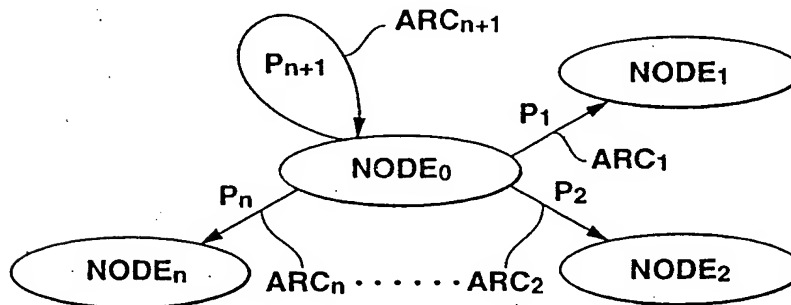
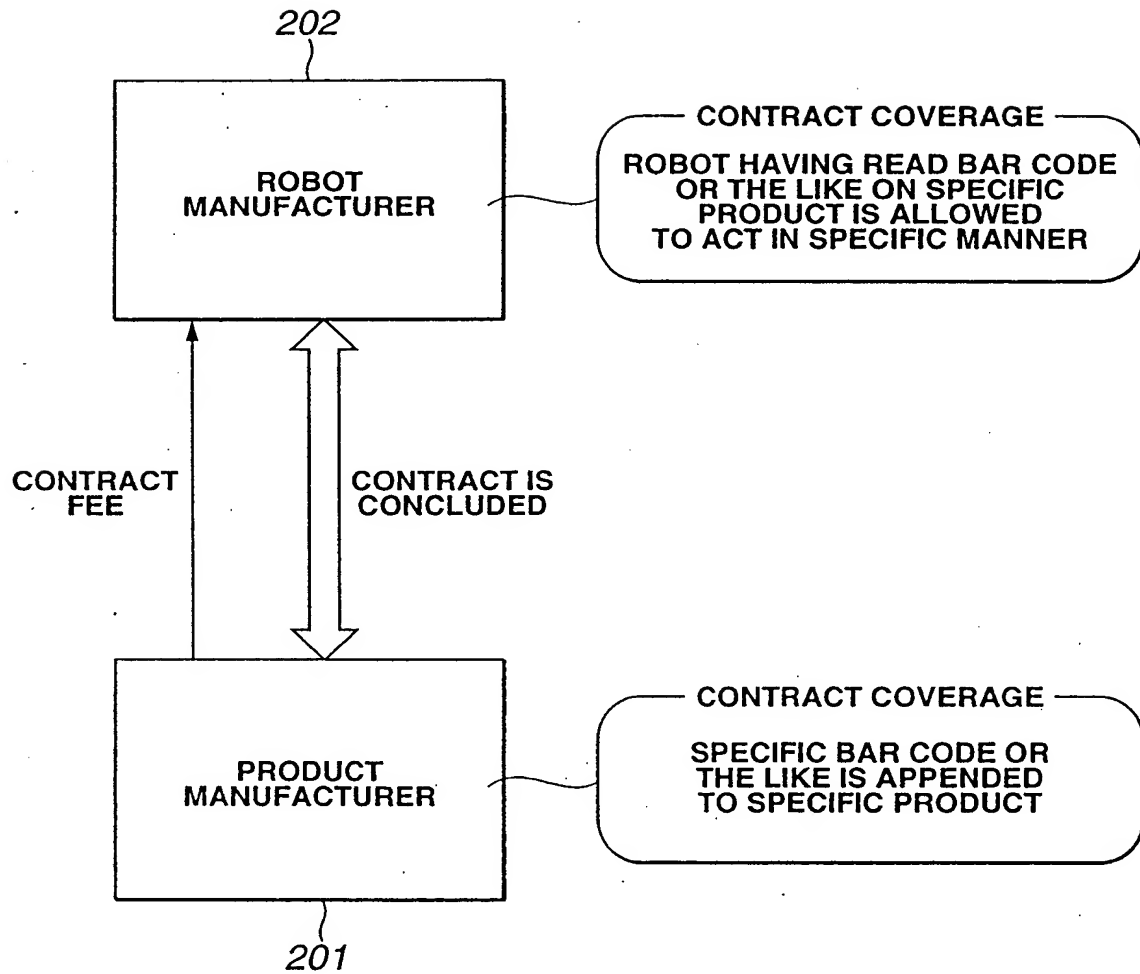


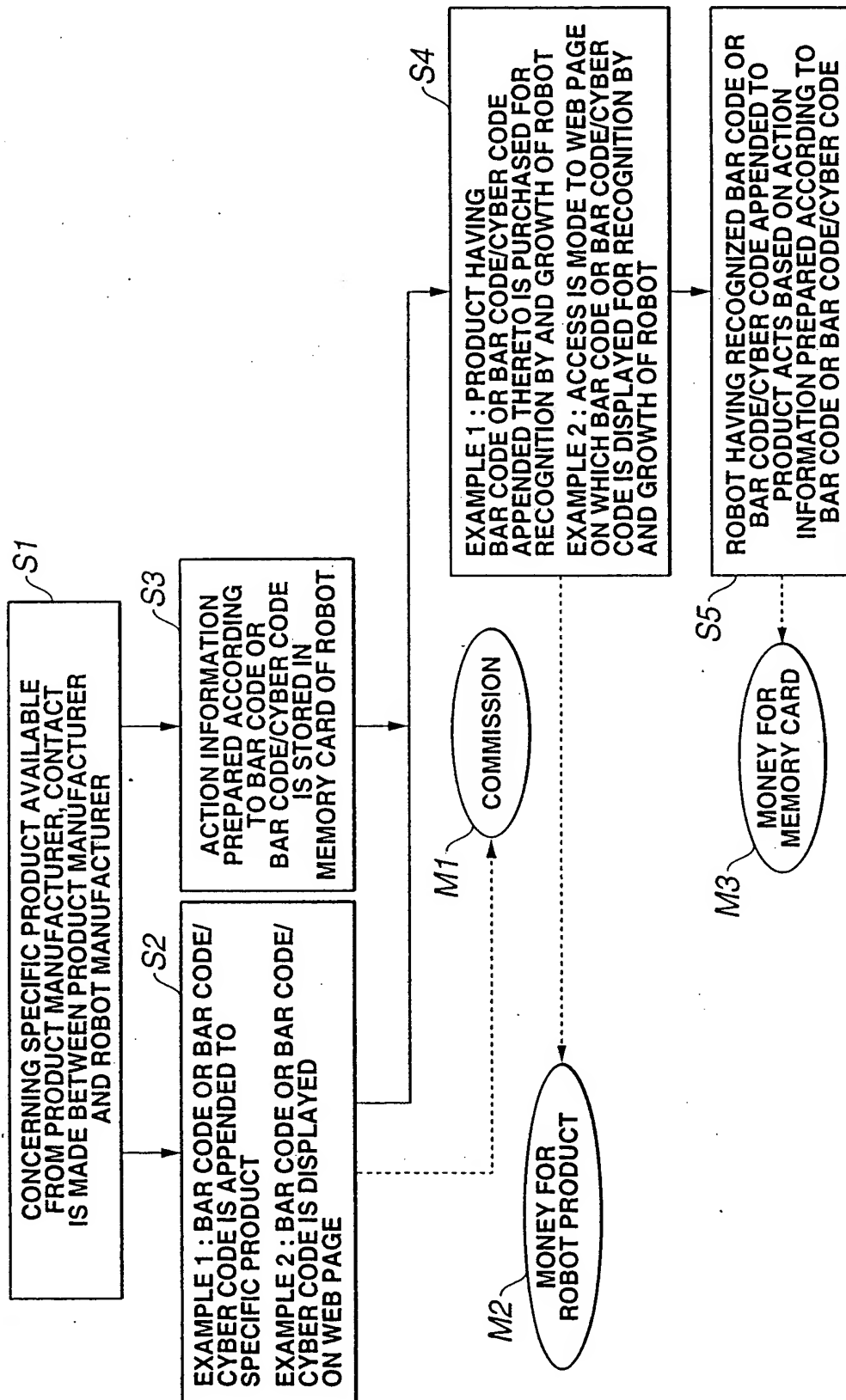
FIG.4

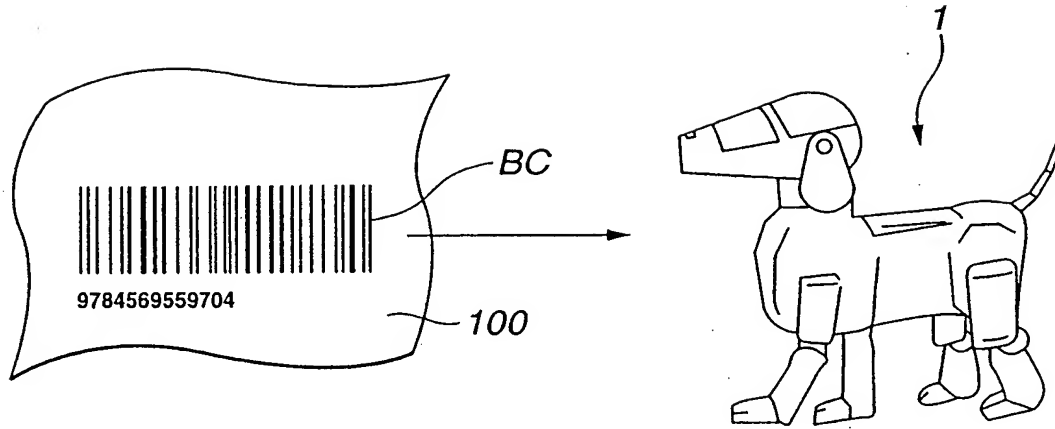
NODE <sub>100</sub>		NODE <sub>120</sub>				PROBABILITY OF TRANSITION TO OTHER NODE (Di)					
NODE 100	INPUT EVENT NAME	DATA NAME	DATA RANGE					NODE 120	NODE 120	NODE 1000	NODE 600
TRANSITION DESTINATION NODE								ACTION 1	ACTION 2	MOVE BACK	ACTION 4
OUTPUT ACTION											
1	BALL	SIZE	0, 1000					30%			
2	PAT								40%		
3	HIT								20%		
4	MOTION									50%	
5	OBSTACLE	DISTANCE	0, 100							100%	
6		JOY	50, 100								
7		SURPRISE	50, 100								
8		SADNESS	50, 100								

FIG.5

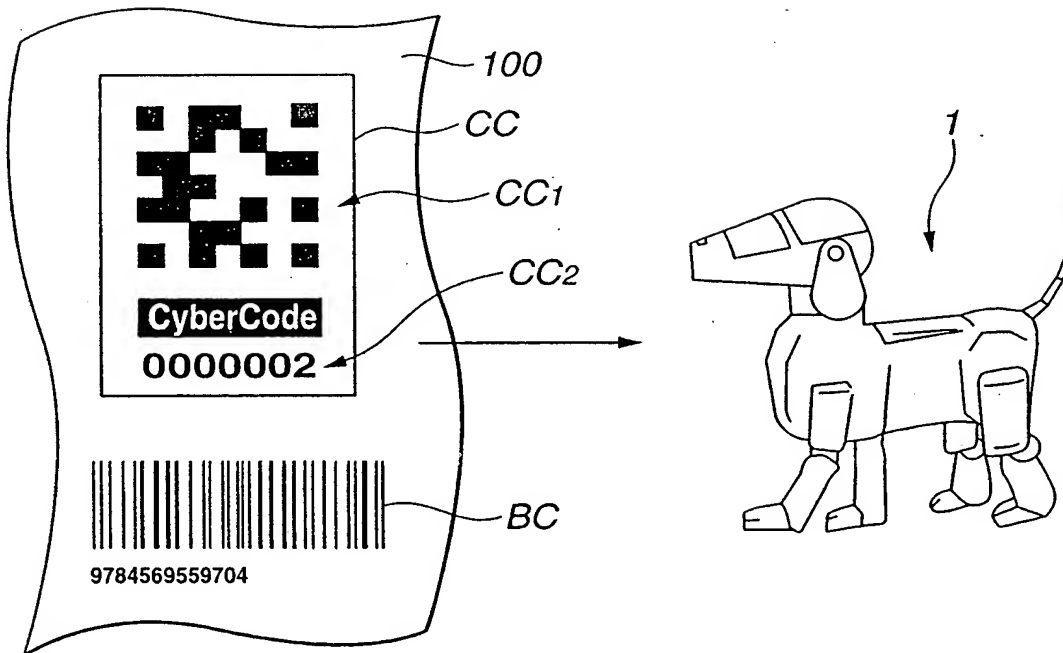


**FIG.6**





**FIG. 8A**



**FIG. 8B**

FIG.9A

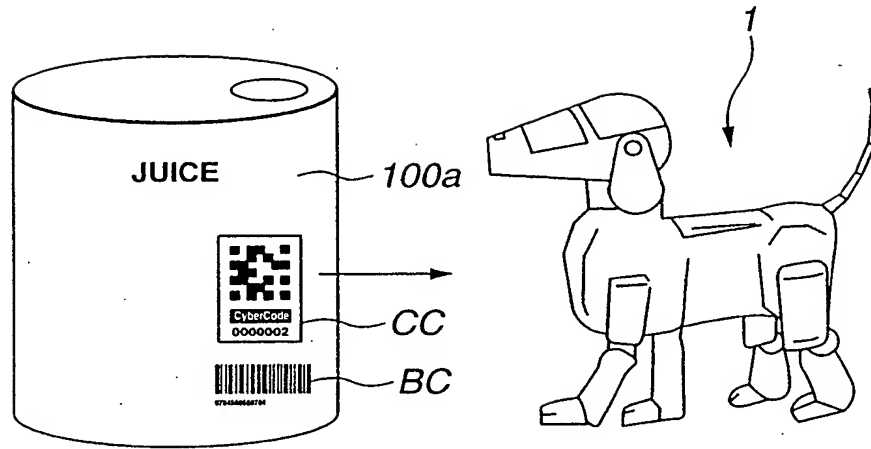


FIG.9B

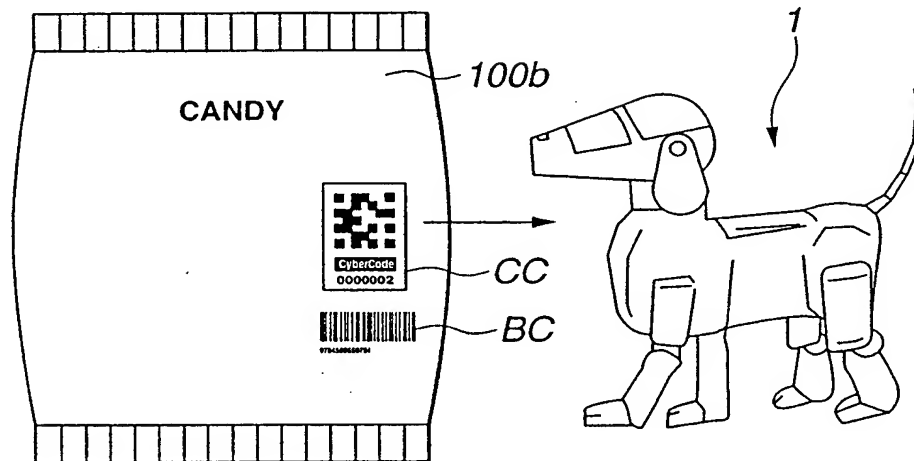
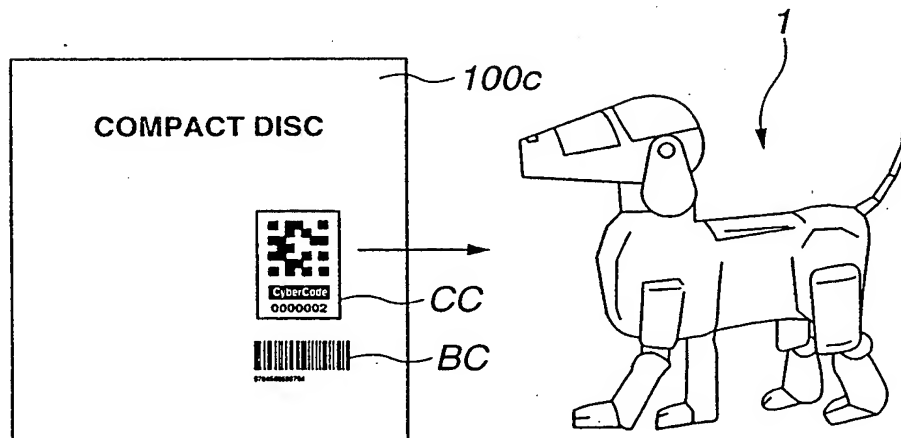
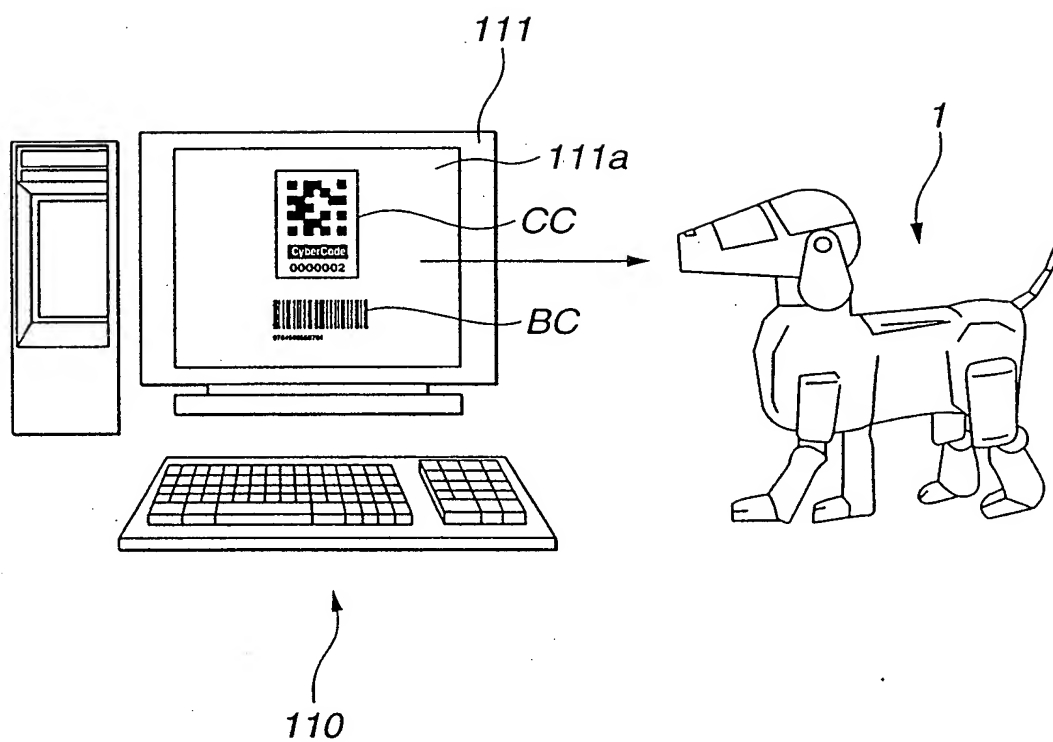


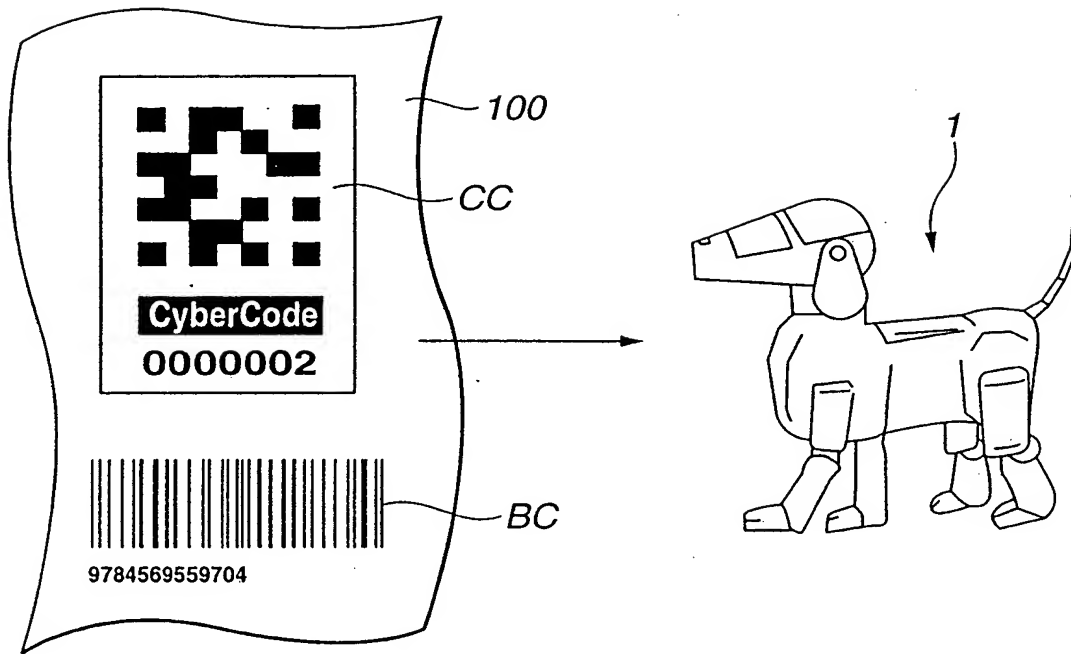
FIG.9C



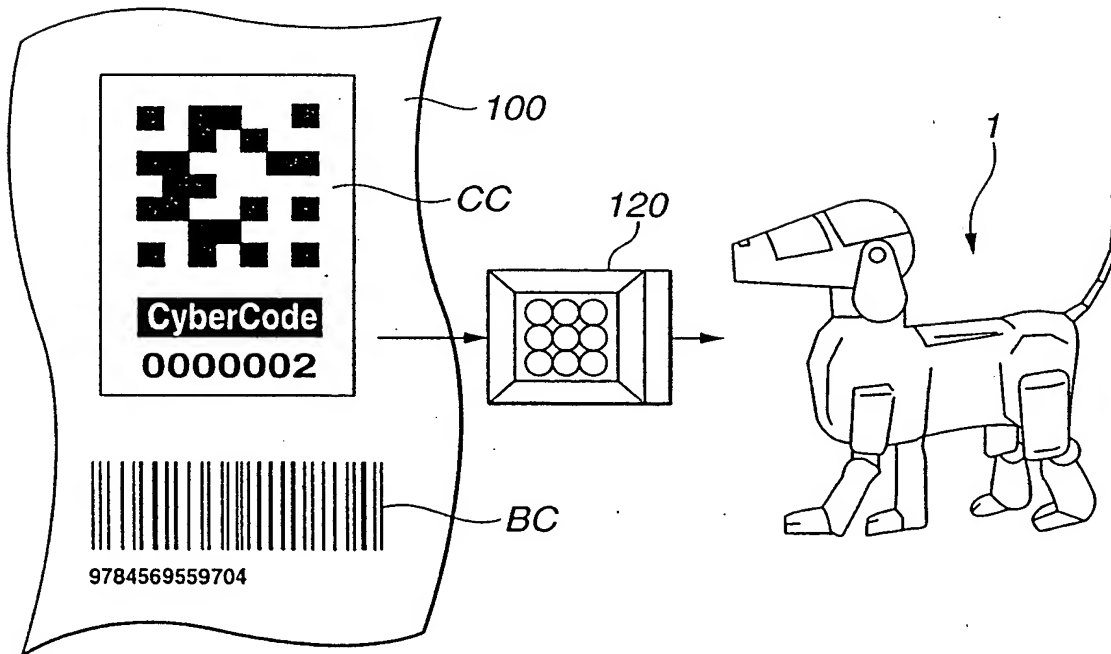




**FIG.10**



**FIG.11A**



**FIG.11B**

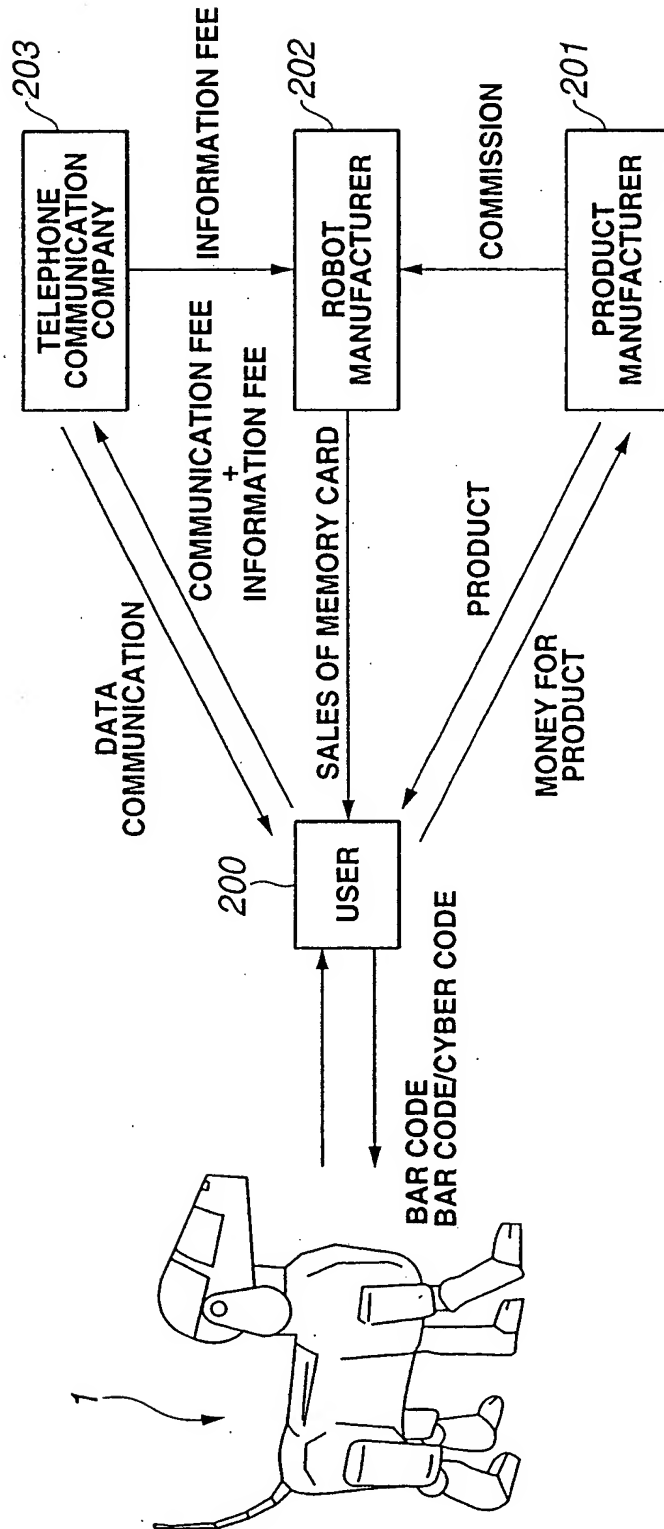


FIG.12

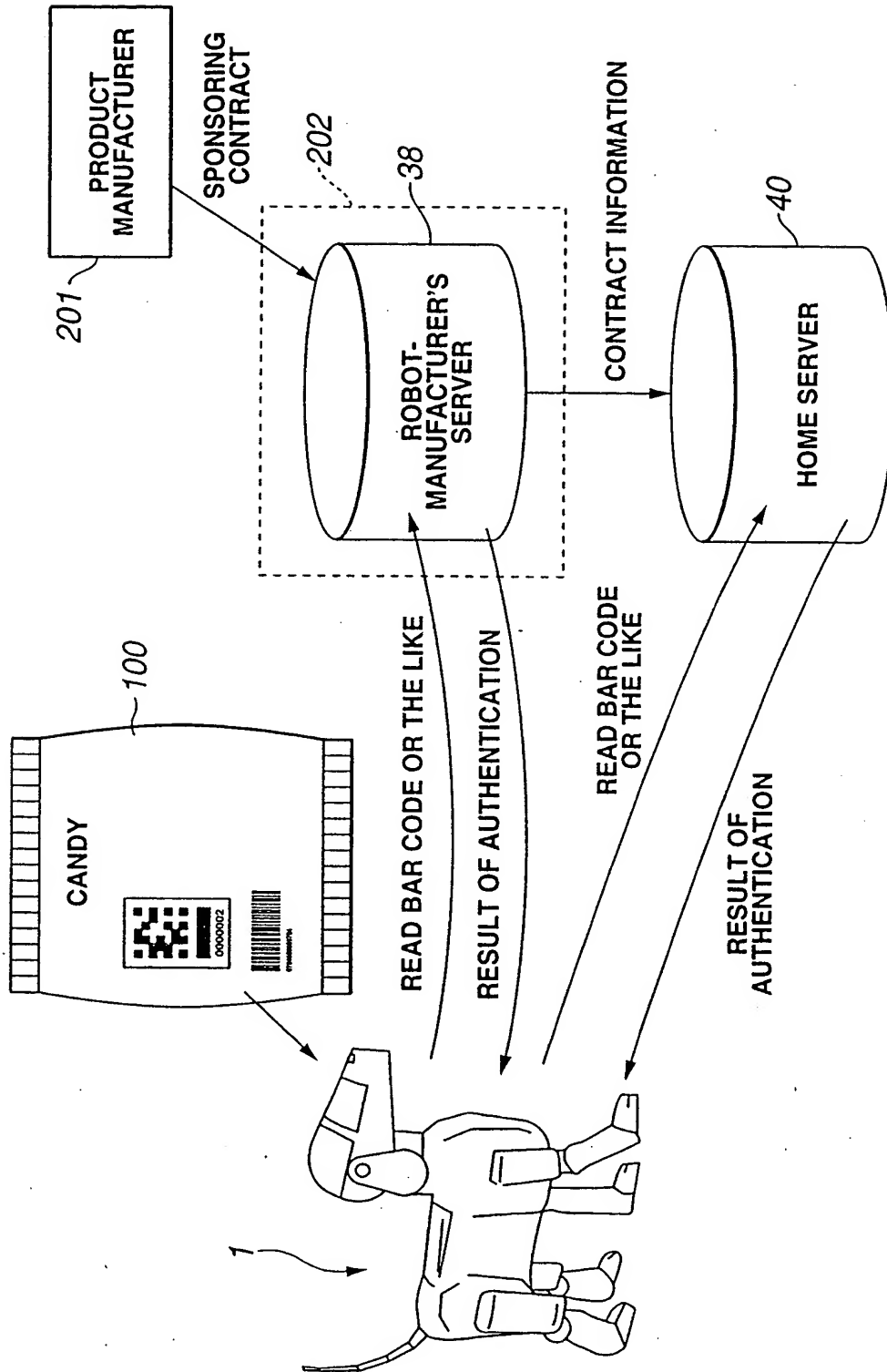


FIG.13

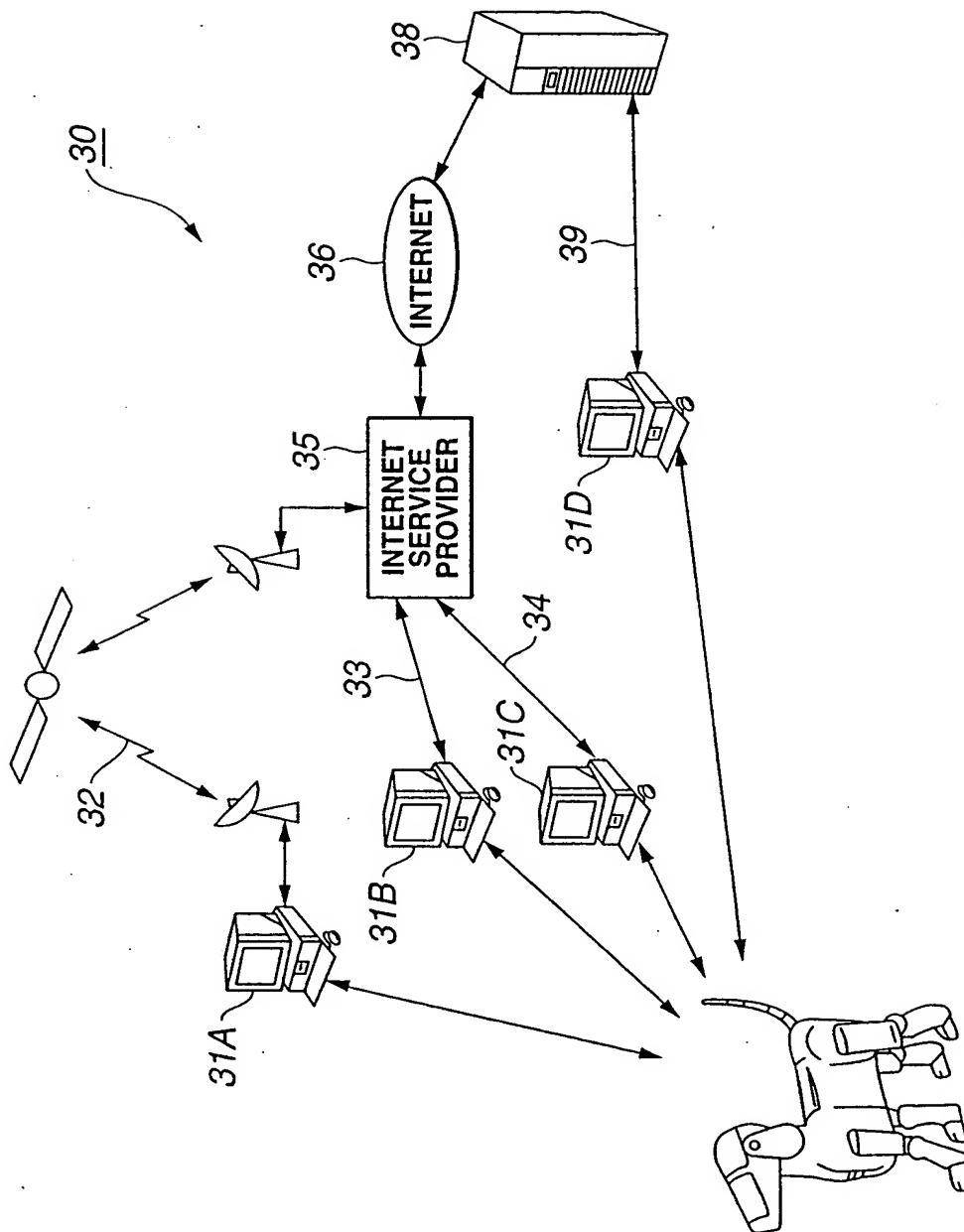


FIG.14

ROBOT-ACCESSORY MANUFACTURER      ROBOT MANUFACTURER      USER

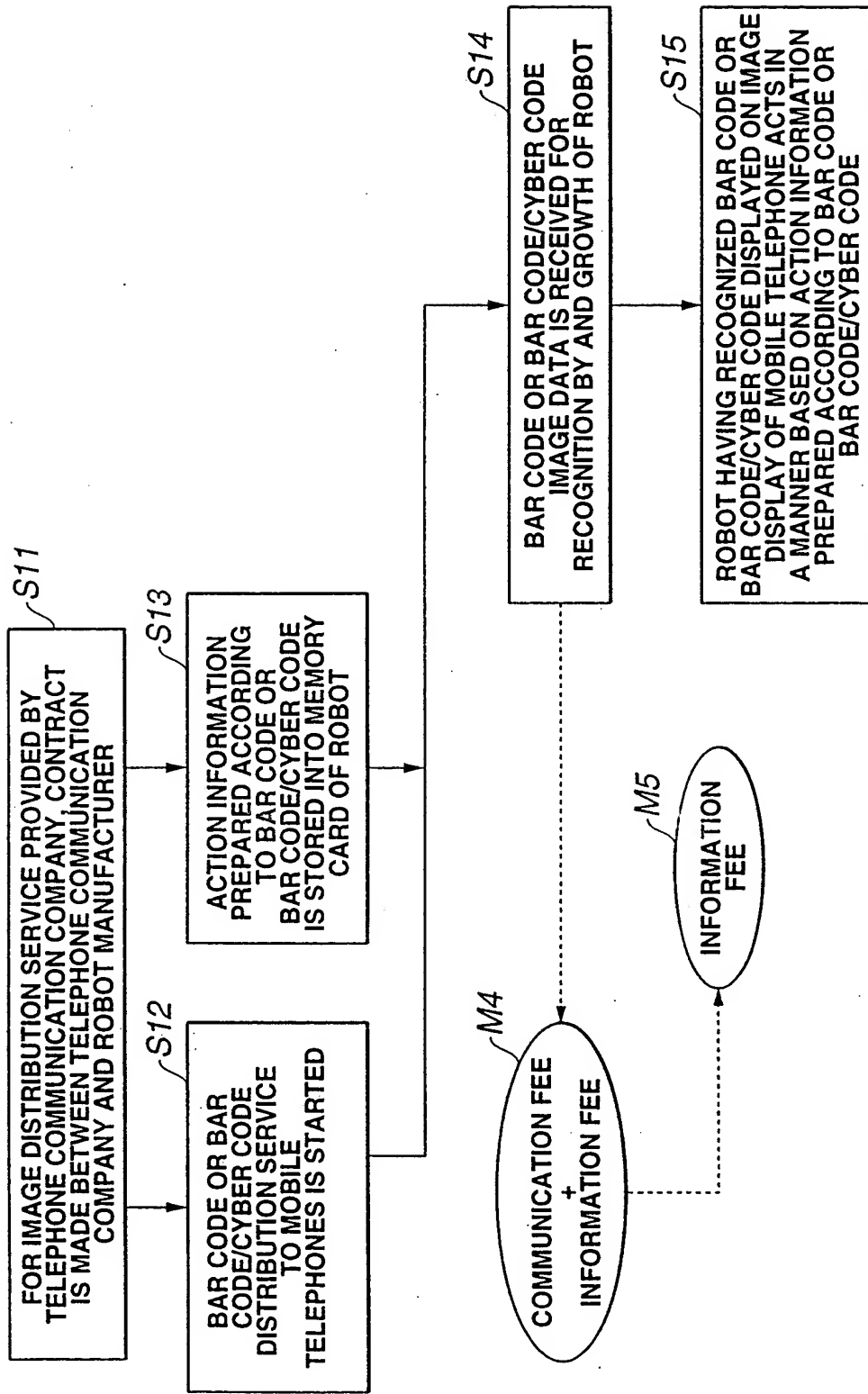


FIG.15

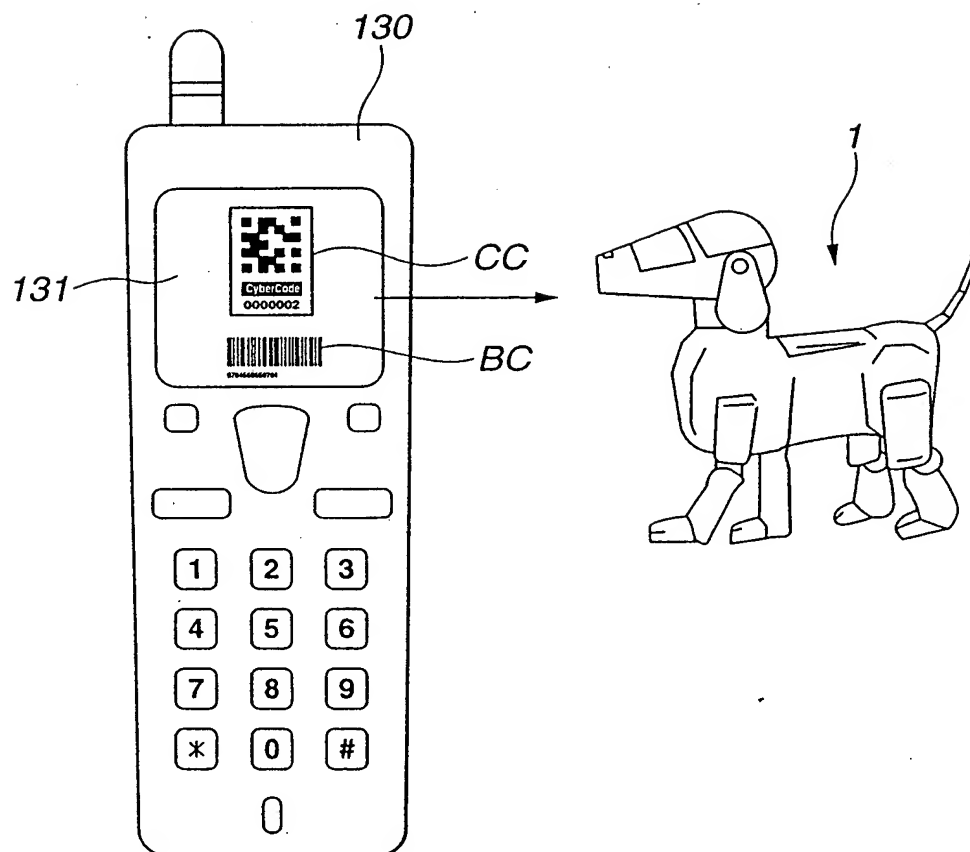


FIG.16

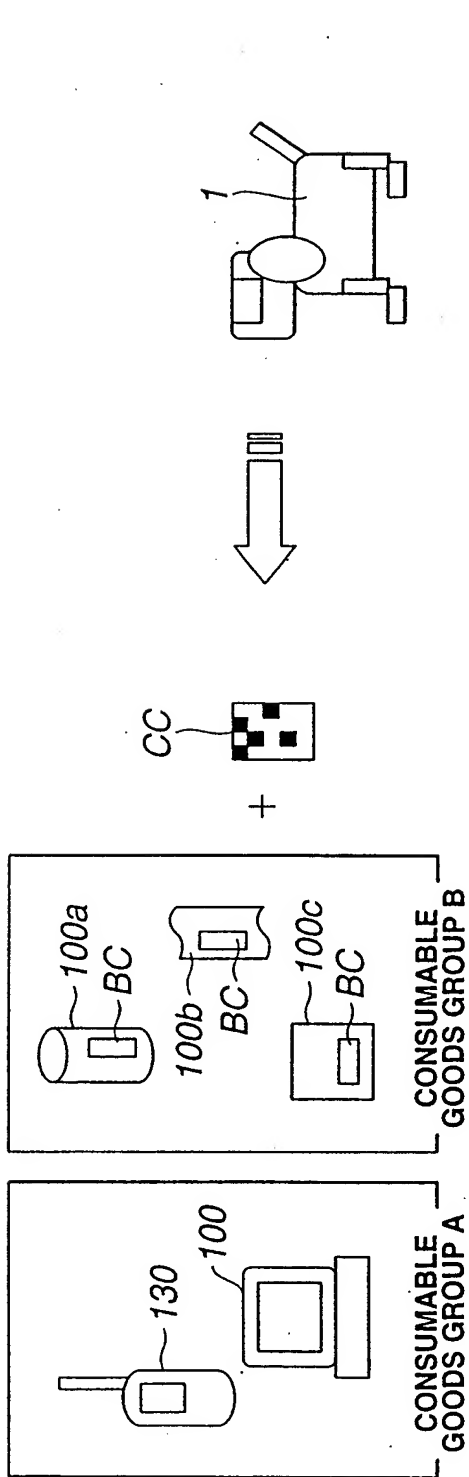


FIG. 17A

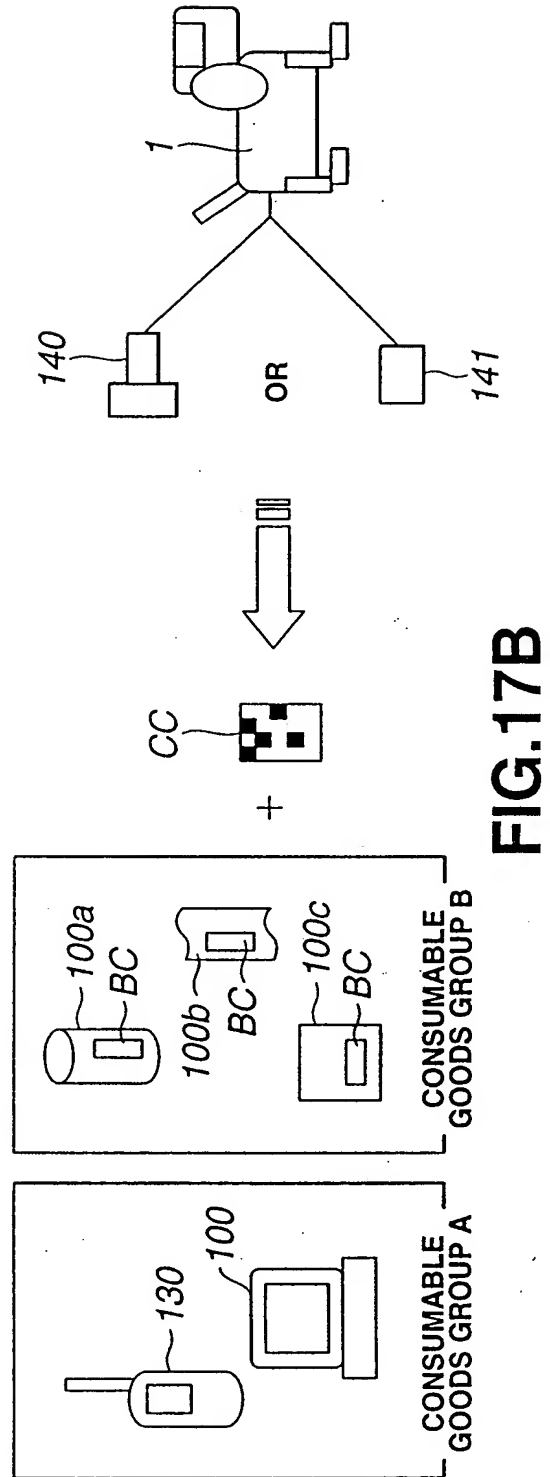


FIG. 17B